

Citation

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Thesis Title:

Robot Path Planning in Dynamic Environments using a Simulated Annealing Based Approach

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Citation:

This research develops and implements a simulated annealing algorithm based approach to find the optimal path for a mobile robot in a dynamic environment with moving obstacles. The approach solves drawbacks occurred in some previous methods and its performance is shown to be superior to that of the previous genetic algorithm based approach. The performance is better in both online and offline processing times as well as in obtaining the optimal solution for path planning of the robot in the dynamic environment.